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Figure 1

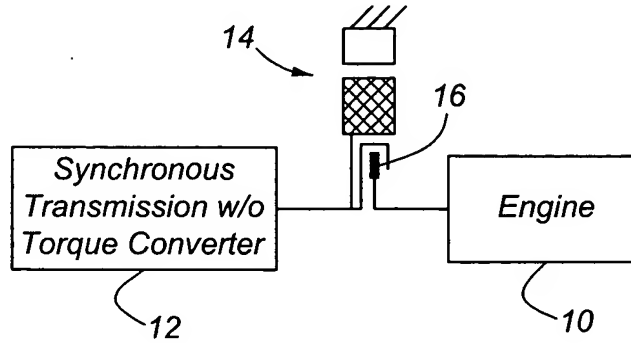
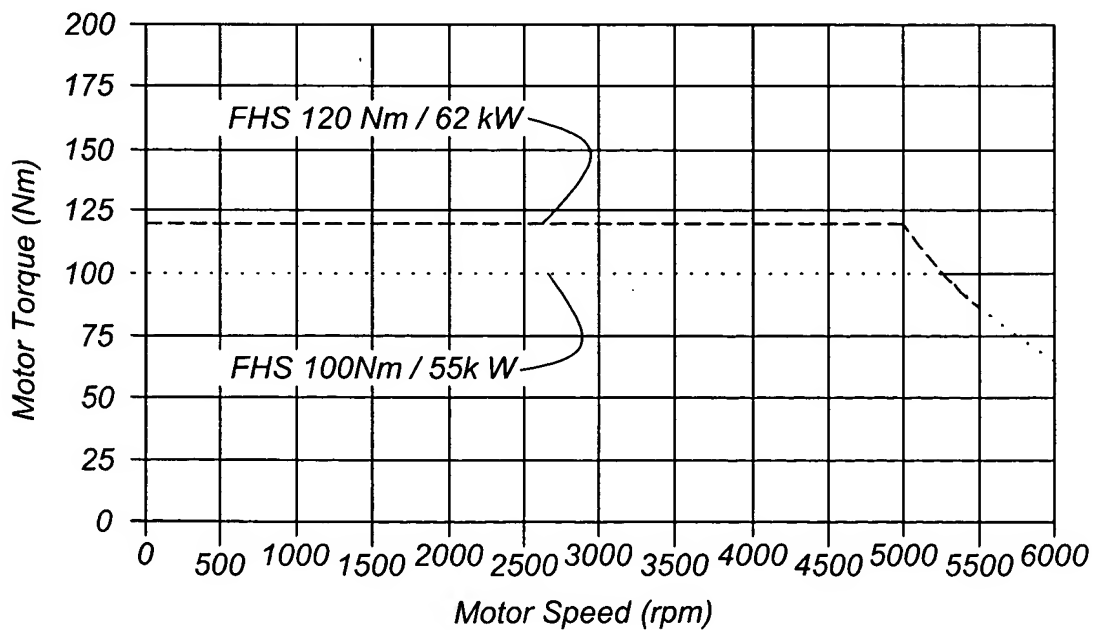


Figure 3

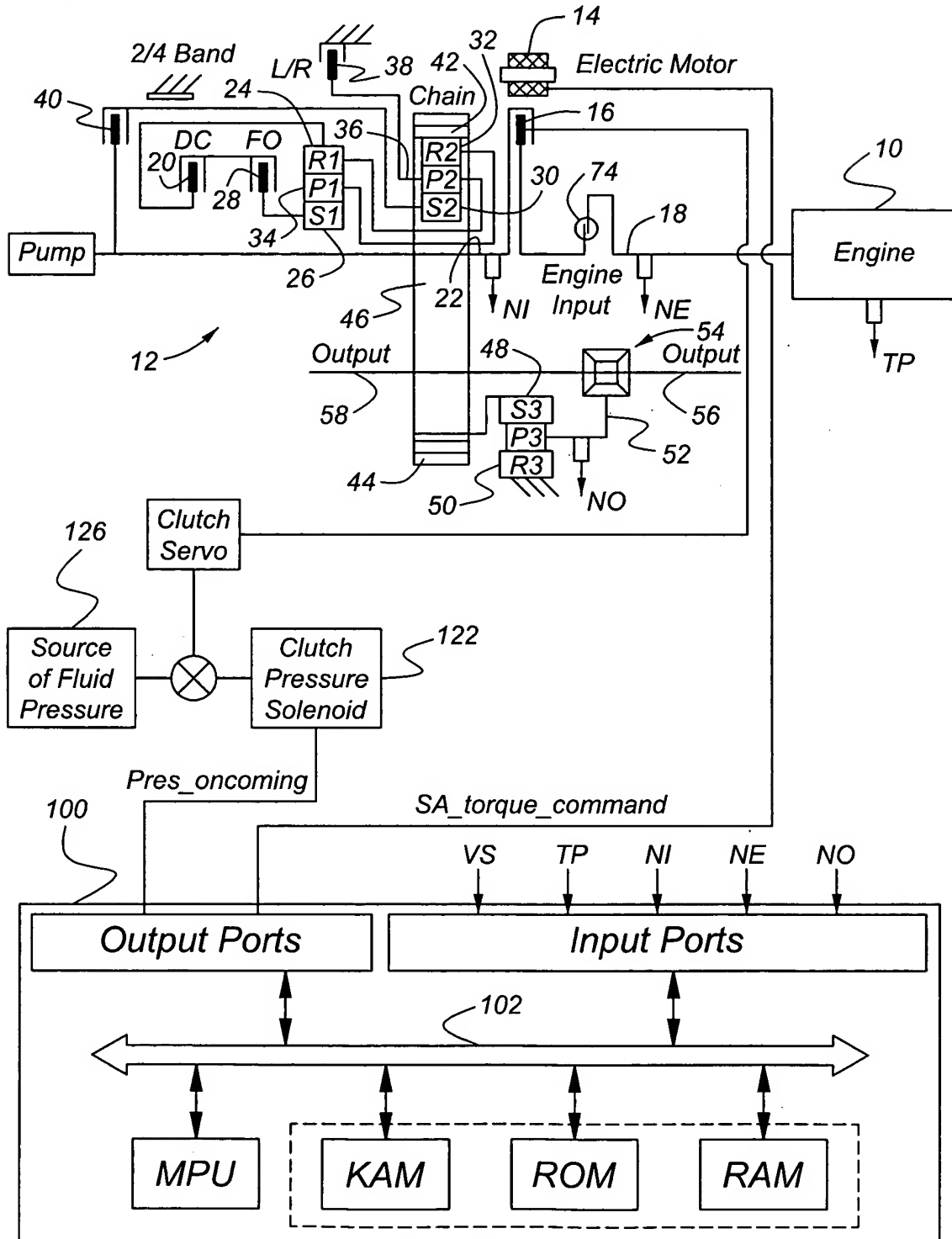
Gear	40	28	26	38	2/4 Band
1st		X		X	
2nd		X			X
3rd		X	X		
4th			X		X
REV	X			X	

Figure 5



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Figure 2



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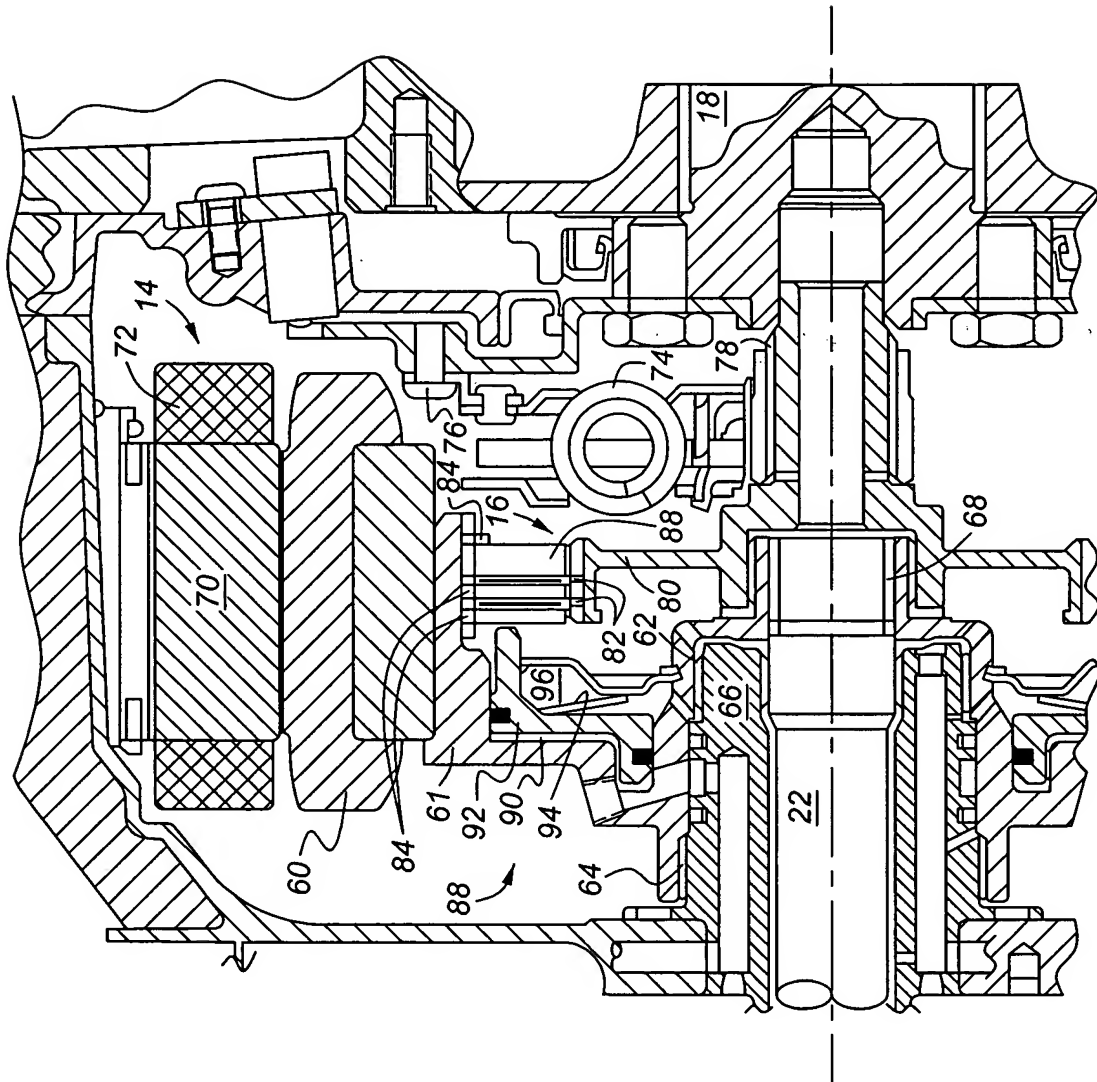


Figure 4

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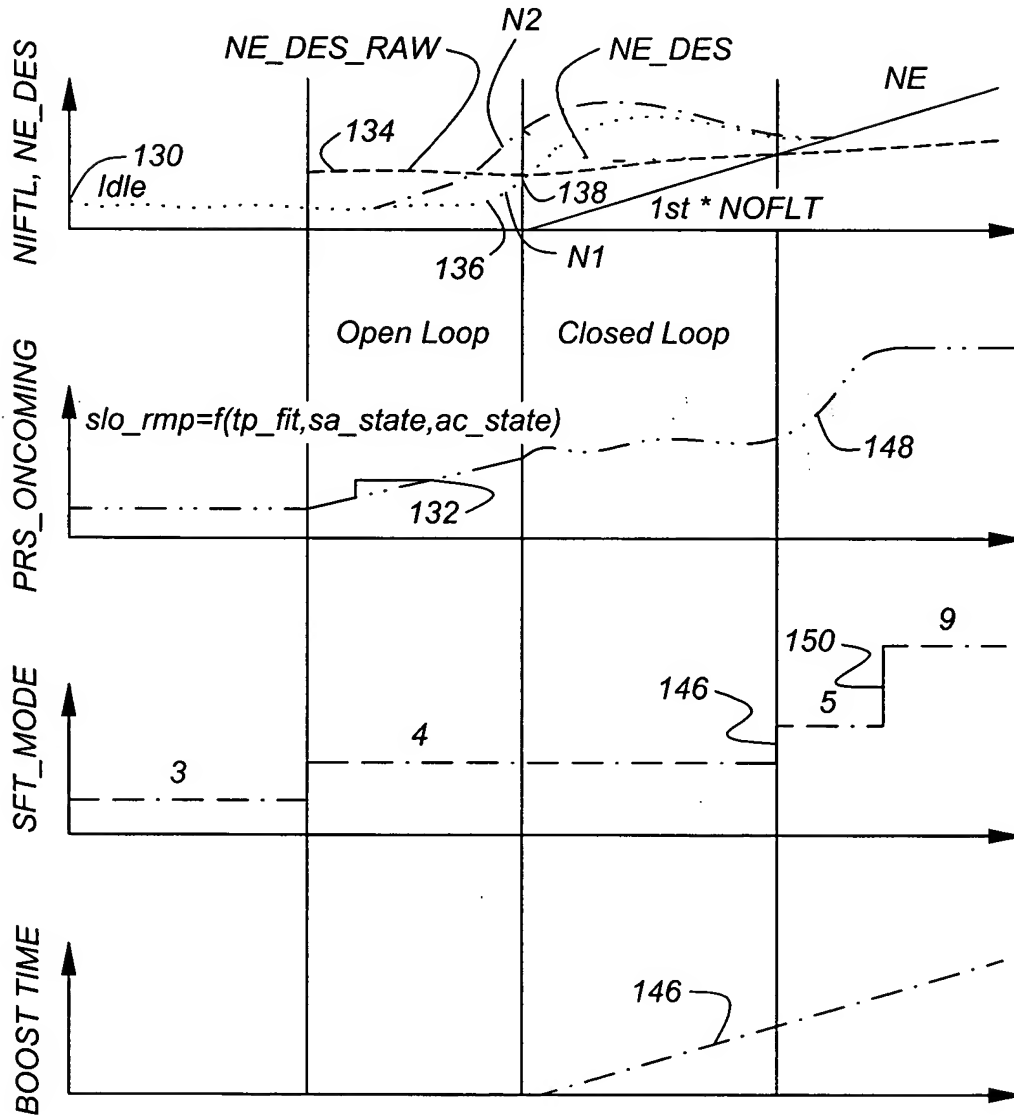


Figure 6

The diagram illustrates a torque control system 100. It begins with a reference velocity VS (162) which is multiplied by a gain $K_{Nov.}$ (164) and added to a feedback signal from a first-order filter (170) to produce a target speed (168). This target speed is compared with a feedback signal from a switch (178) to produce an error signal (172). The error signal is processed by a first-order filter (176) and then a PID control block (184) to produce a torque command (186). This torque command is limited by an up-rate limiter (188) and then compared with a feedback signal from a switch (192) to produce a final torque command (194). The final torque command is multiplied by a gear factor (196) to produce the final torque output (198).

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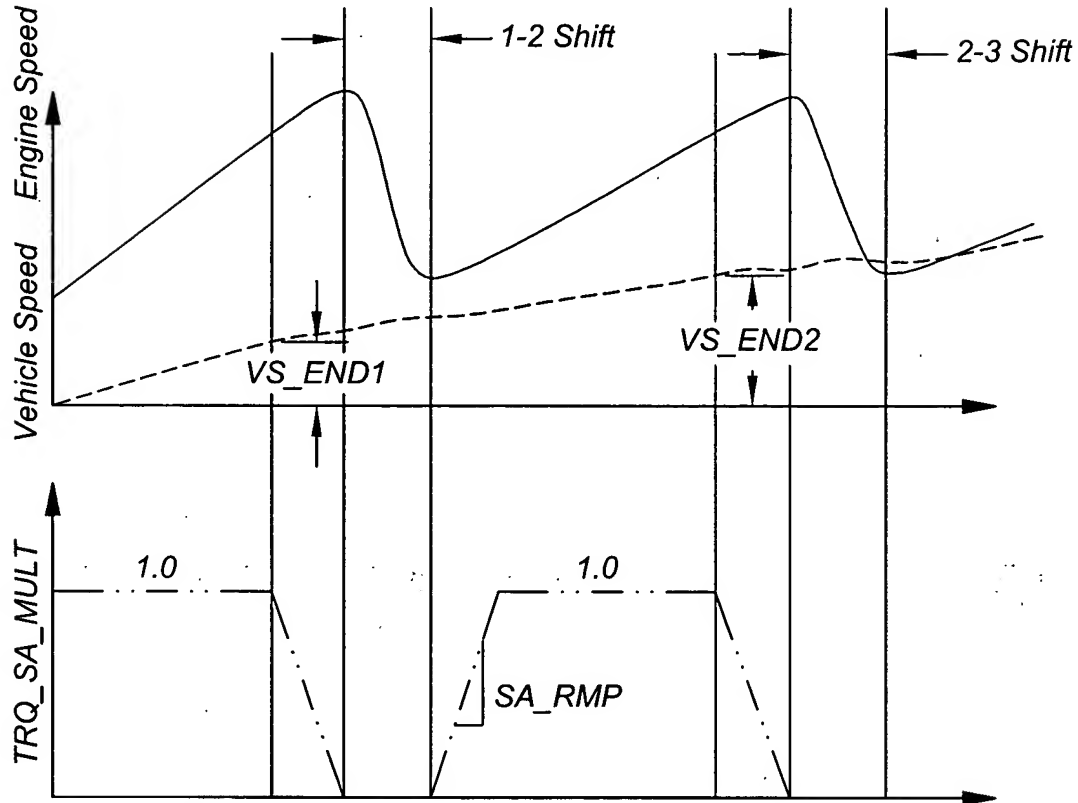


Figure 8

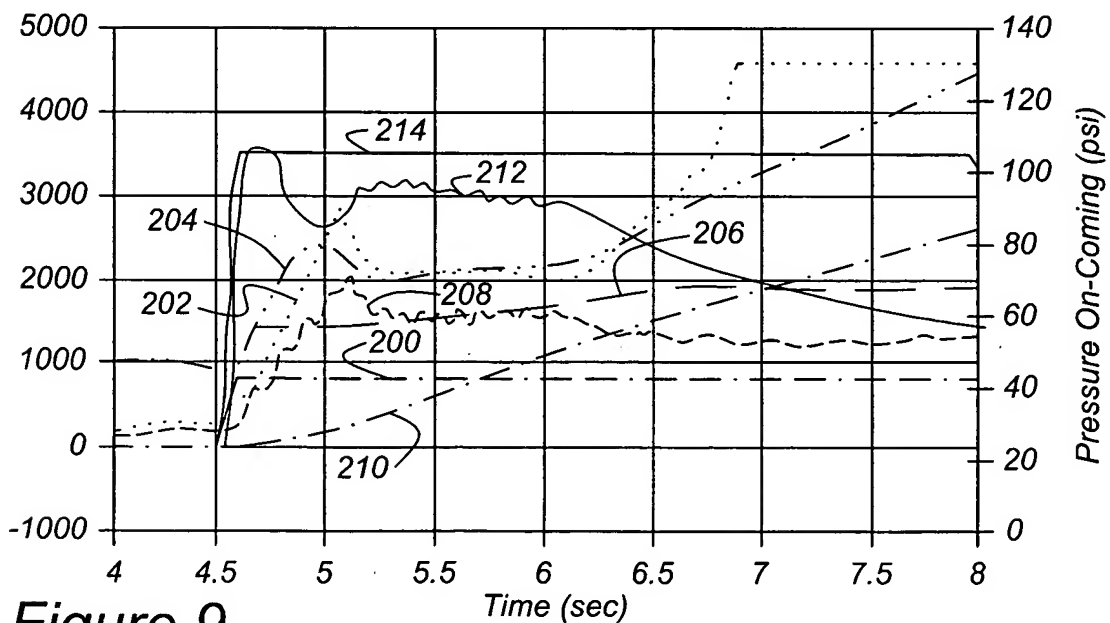


Figure 9

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Figure 10

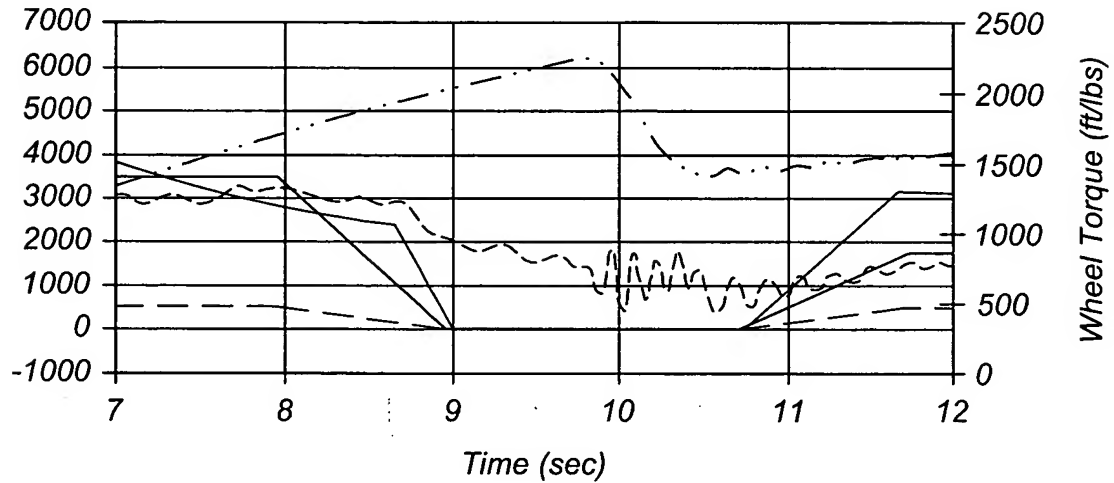


Figure 11

